

Contents

Acknowledgements	iv
Abstract	vi
Kurzfassung	ix
List of Tables	xx
List of Figures	xxi
Chapter 1 Introduction	1
 Part I Context	 7
Chapter 2 Platooning	8
2.1 Definitions	9
2.2 Platooning Control	10
2.2.1 Centralized Control	11

2.2.2	Decentralized Control	12
2.3	Use Cases	13
2.3.1	Inter-Vehicle Distance Adaptation . .	13
2.3.2	Emergency Braking	15
2.3.3	Maintain Platoon	16
Chapter 3	Vehicular Networks	18
3.1	Communications Technologies	19
3.1.1	IEEE 802.11p	20
3.1.2	LTE-V	21
3.1.3	5G-V2X	23
3.1.4	LTE-D2D	24
3.2	Predictive Communications	26
3.2.1	Predictive Quality of Service	27
3.2.2	Environment Aware Communications	28
3.3	Simulation Tools	29
Chapter 4	Scope	35
4.1	Motivations	37
4.1.1	Application Requirements	38
4.1.2	V2V technologies	40
4.1.3	System Layer Prediction	40
4.1.4	Link Level Prediction	43
4.2	Structure	44
Part II	Application Adaptation	49
Chapter 5	Functional Requirements for the PIR	50
5.1	Emergency Braking Use Case	52

5.2	Analysis Methodology	54
5.2.1	Data Processing	54
5.2.2	Linear Regression with Polynomial Features	56
5.3	Results and Analysis	58
5.3.1	Functions Mapping PIR to IVD	58
5.3.2	Application to PIR Prediction in Highway Scenario	63
Chapter 6	Fuel Saving for Platooning	65
6.1	Control Model	68
6.1.1	Platooning Control Algorithm	68
6.1.2	Parameters	73
6.2	Method	75
6.2.1	Fuel Consumption Model for HDPL	75
6.2.2	Objectives	78
6.2.3	Scenario and Simulations	81
6.3	Results and Modeling	85
6.3.1	Phase I	86
6.3.2	Phase II	90
6.3.3	Manoeuvre Performance Modeling	93
6.4	Fuel Saving Optimization	97
6.4.1	Fuel Saving Optimization Problem Setting	97
6.4.2	Optimization Results	101

Part III V2V Technologies	107
Chapter 7 Sidelink Technologies Benchmarking Setup	108
7.1 Benchmarking Setup Implementation	109
7.1.1 Communication Models	110
7.1.2 Transmission Evaluation	111
7.1.3 Use Case	112
7.2 Simulations and Results	115
7.2.1 Simulation Settings and Scenarios	115
7.2.2 Key Performance Indicators	116
7.2.3 Simulation Results	116
7.2.4 Discussion	120
Chapter 8 5G Extensions	124
8.1 Simulation Platform Extension	125
8.1.1 Channel Models	126
8.1.2 Radio Access Technologies	128
8.1.3 Simulator Structure	129
8.2 Channel Models Comparison	130
8.2.1 Scenario	130
8.2.2 Results	131
8.3 Radio Access Technologies Performance	134
8.3.1 Scenario	134
8.3.2 Results	136
Part IV Packet Inter-Reception Time Prediction	140
Chapter 9 PIR Prediction Models	141
9.1 Scenario	142
9.1.1 High-Density Platooning System	143

9.1.2	Simulation Platform	144
9.2	Data Set	146
9.2.1	Target: Packet Inter-Reception Time	146
9.2.2	Environmental Model	149
9.2.3	Features Dimensionality	151
9.3	Prediction based on Kernel Density Estimation	153
9.3.1	Prediction Model Formulation	153
9.3.2	Kernel Density Estimation	155
9.3.3	Selected Results	157
9.4	Conditional Density Estimation	159
9.4.1	Conditional Exponential Distribution	161
9.4.2	Model Evaluation	165
9.4.3	Evaluation and Results	167
Chapter 10	On-the-Fly PIR CDE	174
10.1	Scenario and Data	175
10.1.1	Scenario	176
10.1.2	Data Set	177
10.2	Preliminary Analysis	179
10.3	Extended Environmental Model	181
10.3.1	Annulus-Sector Model	183
10.3.2	Learning Approaches	191
10.3.3	Model Parameters Evaluation	193
10.4	On-the-Fly Application	196
10.4.1	On-the-Fly Learning Performance	197
10.4.2	On-the-Fly Prediction	200
Chapter 11	Prediction to Forecast	203
11.1	Sensitivity Analysis	204
11.1.1	Method	205

11.1.2 Results	206
11.1.3 Input Prediction	208
11.2 Local to Global Knowledge	211
11.2.1 Method	212
11.2.2 Results	215
 Part V Link Level Prediction	 219
 Chapter 12 Environment-Aware Communications – Setup	 220
12.1 Link Improvement for Fuel Saving	222
12.1.1 Link Level Challenges of the Vehicu- lar Environment	222
12.1.2 Doppler Frequency Shift in HDPL . .	224
12.1.3 Impact on Fuel Saving	227
12.2 Sensor-Based Predictive Communications . .	228
12.2.1 LTE-D2D Simulator Extension	229
12.2.2 Sensor-Based Predictive Communica- tion	233
12.3 HDPL Control Algorithms and Models	236
12.3.1 Control Algorithms	236
12.3.2 Vehicle Model	240
12.4 Scenarios Implementation	242
 Chapter 13 Environment-Aware Communications – Applica- tions	 245
13.1 Maintain Platoon	246
13.1.1 Scenario Description	246
13.1.2 HDPL Functional Performance	249
13.2 Collaborative Collision Avoidance	255
13.2.1 Scenarios Description	255

13.2.2 Results	259
13.2.3 Discussion	262
Chapter 14 Conclusion	266
14.1 Contributions and Findings	267
14.2 Outlook and Future Work	272
Acronyms	280
Symbol List	289
Bibliography	292